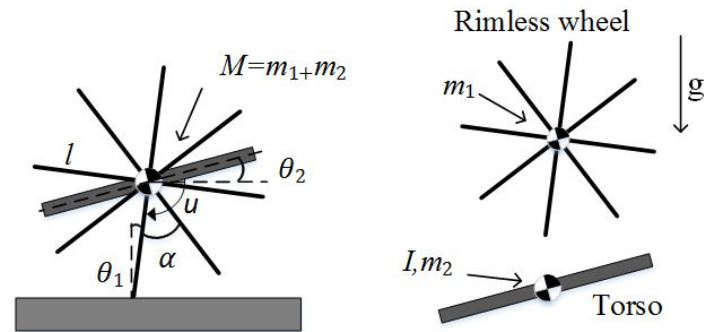# Analysis and Control of Limit Cycle Walking Based on Linearized Equation of Motion

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- An underactuated rimless wheel with torso was developed and the mathematical model was analysed.

- The initial and terminal boundary conditions were derived and the feedback control system was proposed for target walking states generation.

- The extension was made to the bipedal walker to generate target walking states.

Underactuated rimless wheel with torso